

This listing of claims will replace all prior versions, listings, of claims in the application:

**Listing of Claims:**

1. (previously presented) A robotic mechanism, comprising:  
a support base, an end effector and a biasing member having opposed ends and attached at one of said opposed ends to the support base and attached at the other of said opposed ends to the end effector; and  
at least three cables each connected at a first end thereof to said end effector and said at least three cables having second ends being attached to an associated positioning mechanism for moving the second ends of said at least three cables to position said end effector in a selected position in space, a length of each of said at least three cables between said end effector and said associated positioning mechanism being fixed, said biasing member applying force on the end effector with respect to the support base for maintaining tension in said at least three cables.
2. (cancelled)
3. (previously presented) The robotic mechanism according to claim 1 including a computer controller connected to each said positioning mechanism for synchronizing the movement of each positioning mechanism with respect to the other positioning mechanisms to control movement of said end effector.
4. (cancelled)
5. (cancelled)
6. (previously presented) The robotic mechanism according to claim 1 wherein said at least three cables are three pairs of cables with the first ends of

each pair of cables attached to the end effector and the second ends of each pair of cables being attached to said associated positioning mechanism, wherein each positioning mechanism includes an actuator for moving the second ends of the associated pair of cables independently of the other pairs of cables, each pair of cables having the first ends of the pair of cables attached to the end effector and the second ends of the pair of cables being attached to its associated actuator in such a way that two cables of each pair of cables are parallel to each other and define a parallelogram so that the robotic mechanism has three degrees of freedom so that during movement of the end effector the orientation of the end effector remains fixed so that the robotic mechanism has three degrees of freedom.

7. (cancelled)

8. (original) The robotic mechanism according to claim 1 wherein said biasing member is a spring.

9. (previously presented) The robotic mechanism according to claim 1 wherein said biasing member is selected from a group of powered cylinders consisting of hydraulically, pneumatically, and electrically powered cylinders having an adjustable length.

10. (previously presented) The robotic mechanism according to claim 1 wherein said biasing member is pivotally attached to said end effector and said support base using universal joints.

11-52. (cancelled)

53. (previously presented) The robotic mechanism according to claim 1 said end effector includes a mounting mechanism for receiving a tool to be mounted on the end effector.